

**AMENDMENTS TO THE SPECIFICATION**

**Page 3**

**Please amend the paragraph beginning on line 9 to read as follows:**

~~DISCLOSURE OF THE INVENTION~~

~~PROBLEMS TO BE SOLVED BY THE INVENTION~~

[0005]

A conventional manipulator with multiple degrees of freedom employs wire as a drive power transmitting means from a drive unit. Bending of an articulation and opening/closing of the gripping portion are achieved by winding up wire with a drive unit.

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**Please amend the paragraph beginning on line 9 to read as follows:**

[0009]

Third, there is a problem that wire is difficult to sterilize and clean. Thus, in the conventional manipulator with multiple degrees of freedom, its sterilization and cleaning before and after surgery are very complicated.

**SUMMARY OF THE INVENTION**

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**Please amend the paragraph beginning on line 2 to read as follows:**

~~MEANS FOR SOLVING THE PROBLEM~~

[0013]

The present invention concerns a manipulator with multiple degrees of freedom which is driven by a driving means. More particularly, it concerns a manipulator with multiple degrees of freedom used for minimally invasive surgery such as abdominal cavity surgery. As the driving means, a drive unit including a reciprocatory output axis, for example, an actuator may be used.

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**Please amend the paragraph beginning on line 9 to read as follows:**

~~EFFECTS OF THE INVENTION~~

[0031]

The present invention enables the durability and control accuracy to be raised by employing a link mechanism as a drive power transmitting means. Further, the present invention facilitates sterilization, cleaning and attachment/detachment to/from a driving means.

**After line 16, please add the following new paragraphs:**

**BRIEF DESCRIPTION OF THE DRAWINGS**

FIG. 1 is a diagram showing a bending forceps system including a manipulator with multiple degrees of freedom (bending forceps) according to an implementation of the present invention.

FIG. 2 is a perspective view of the front end portion of the bending forceps.

FIG. 3 is a top view of the front end portion of the bending forceps.

FIG. 4 is a side view of the front end portion of the bending forceps.

FIG. 5 is a diagram showing an action of a first link mechanism.

FIG. 6 is a diagram showing an action of the first link mechanism.

FIG. 7 is a diagram showing an action of a third link mechanism.

**Please amend the paragraph beginning on line 17 to read as follows:**

~~BEST MODE FOR CARRYING OUT THE INVENTION~~ **DETAILED DESCRIPTION OF THE  
PREFERRED EMBODIMENTS**

[0032]

Hereinafter, preferred embodiments (implementations) of the present invention will be described in detail by way of example with reference to accompanying drawings.

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**Beginning on line 22, please delete the following paragraphs:**

**~~BRIEF DESCRIPTION OF THE DRAWINGS~~**

~~{0068}~~

~~{FIG. 1} FIG. 1 is a diagram showing a bending forceps system including a manipulator with multiple degrees of freedom (bending forceps) according to an implementation of the present invention.~~

~~{FIG. 2} FIG. 2 is a perspective view of the front end portion of the bending forceps.~~

~~{FIG. 3} FIG. 3 is a top view of the front end portion of the bending forceps.~~

~~{FIG. 4} FIG. 4 is a side view of the front end portion of the bending forceps.~~

~~{FIG. 5} FIG. 5 is a diagram showing an action of a first link mechanism.~~

~~{FIG. 6} FIG. 6 is a diagram showing an action of the first link mechanism.~~

~~{FIG. 7} FIG. 7 is a diagram showing an action of a third link mechanism.~~